

## Abstract

The present invention relates to a method for correcting the position of the angle marks of an incremental gear of a rotary speed sensor and/or rotary angle sensor of an internal combustion engine and to a system therefor.

- 5 The present invention is characterized by the following steps:
- a) recording the angle marks (k) using the rotary speed sensor and/or the rotary angle sensor (1,2,3,4),
  - b) measuring the combustion chamber pressure ( $p_{zyl}(1), p_{zyl}(2), \dots, p_{zyl}(2M/Z)$ ) in the respective cylinder (5a, 5b) of the internal combustion engine,
  - 10 c) assigning a measured pressure value ( $p_{zyl}(1), p_{zyl}(2) \dots p_{zyl}(2M/Z)$ ) to the recorded angle mark positions ( $\phi_{inkr,real}(k)$ ),
  - d) possibly correcting the measured pressure values ( $p_{zyl}(1), p_{zyl}(2) \dots p_{zyl}(2M/Z)$ ) in a signal-conditioning device (12),
  - e) storing the recorded angle mark positions ( $\phi_{inkr,real}(k)$ ) with the appertaining, measured
  - 15 pressure values ( $p_{zyl}(1), p_{zyl}(2) \dots p_{zyl}(2M/Z)$ ) in a measured value table (11),
  - f) storing of the ideal pressure values  $p_{zyl,ideal}(1), p_{zyl,ideal}(2), \dots, p_{zyl,ideal}(2M/Z)$  derived at the ideal angle mark positions ( $\phi_{inkr,ideal}(k)$ ) in a reference table (9),
  - g) comparing the pressure values ( $p_{zyl}(1), p_{zyl}(2) \dots p_{zyl}(2M/Z)$ ), that were measured and possibly preprocessed in the signal-conditioning device (12) to the ideal pressure values
  - 20  $p_{zyl,ideal}(1), p_{zyl,ideal}(2) \dots p_{zyl,ideal}(2M/Z)$ ,
  - h) determining deviations ( $\Delta\phi_{KW,Korr}$ ) of the measured angle mark positions ( $\phi_{inkr,real}(k)$ ) from the ideal angle mark positions ( $\phi_{inkr,ideal}(k)$ ), at the corresponding cylinder pressure values ( $p_{zyl}(1) = p_{zyl,ideal}(1), p_{zyl}(2) = p_{zyl,ideal}(2), p_{zyl}(2M/Z) = p_{zyl,ideal}(2M/Z)$ ) in an evaluation unit (13), and
  - 25 i) correcting the measured angle mark positions ( $\phi_{inkr,real}(k)$ ) by the deviations determined ( $\Delta\phi_{KW,Korr}$ ).

Fig. 2